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Dynamic Multiscale Visualization of Flight Data

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Abstract: We present a novel set of techniques for visualization of very large data sets encoding flight information obtained from Air Traffic Control. The aims of our visualization are to provide a smooth way to explore the available information and find outlier spatio-temporal patterns by navigating between fine-scale, detail, views on the data and coarse overviews of large areas and long time periods. To achieve this, we extend and adapt several image-based visualization techniques, including animation, density maps, and bundled graphs. In contrast to previous methods, we are able to visualize significantly more information on a single screen, with limited clutter, and also create real-time animations of the data. For computational scalability, we implement our method using GPU-accelerated techniques. We demonstrate our results on several real-world data sets ranging from hours over a country to one month over the entire world.

1 INTRODUCTION

In the last years, the availability of large and accurate data sources describing the motion of various types of vehicles, *e.g.* airplanes, vessels, automobiles, and pedestrians, has massively increased (Andrienko et al., 2007; Keim et al., 2007; Andrienko et al., 2011; Andrienko et al., 2012; PlaneFinder, 2013). The availability of such movement data sets can help in a wide range of analyses and use-cases, such as Air Traffic Control (ATC), epidemics propagation, and crisis situation analysis.

Within this context, we focus on the analysis of airplane movement data sets. Such data sets consist of several airplane trajectories, or trails, each one being in turn a temporal sequence of data points describing the position, height, velocity, flight direction vector (and possibly more attributes) of a single airplane over its flight time span. Visualization of flight trails can assist in numerous ATC scenarios, such as finding and explaining historical flight outliers; understanding the correlation between flight congestion and weather patterns; training of ATC controllers; and better planning of flight routes over given spatio-temporal intervals (Bilimoria et al., 2001; Hurter et al., 2009; Hurter et al., 2013; Thales, Inc., 2013; Eurocontrol, 2013).

However, visualizing large trail data sets poses several challenges, of which we consider here the following:

Computational scalability: Movement data sets are by their nature orders of magnitude larger than their static counterparts. For instance, Fig. 1 shows a single day of air traffic over France, which contains 20K trajectories, each

having hundreds of data points (one data point is recorded every 4 minutes). A data set for the air traffic over the entire world and over several weeks will easily have millions of trails. Generating real-time visualizations from such data sets is clearly a computational challenge.

Visual scalability: Besides the computational challenge, large trail data sets will also contain many high-density traffic regions. In turn, visualizing such regions will create visual clutter and occlusions. Moreover, if we want to depict not just spatial positions, but additional attributes such as speed, flight ID, and flight height, the information density increases even further.

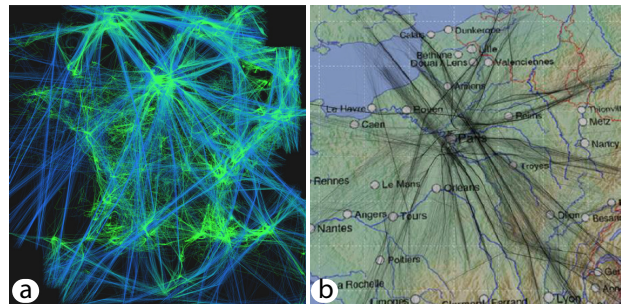


Figure 1: (a) Flights over France, July 5th, 2006, visualized with (Hurter et al., 2009), color-coded by height. (b) Zoom-in over Paris area.

In this paper, we present a visualization system for air traffic that aims to address the above challenges. In contrast to ATC systems that address more specific use-

cases (Thales, Inc., 2013; Eurocontrol, 2013; Gaspard-Boulin et al., 2003; Hurter et al., 2009), our goal is to efficiently and effectively visualize attributed trails over large time and space intervals. We achieve visual scalability by several level-of-detail, or multiscale, techniques: animation, density maps, and graph bundling. We achieve computational scalability by implementing the above techniques efficiently on the GPU. Overall, our contribution extends earlier work in trail visualization (Scheepens et al., 2011; Hurter et al., 2009; Hurter et al., 2013) with several temporal attributes, on the one hand, and making the visualization suitable for large data sets, on the other hand. We demonstrate our visualization on both medium-scale data sets (French air traffic, one week) and very large data sets (the world, one month).

The structure of this paper is as follows. Section 2 overviews related work in the area of trail visualization. Section 3 introduces the proposed visualization techniques. Section 4 presents several visualization results for the analysis of country-scale and world-scale air traffic. Section 5 discusses our techniques. Section 6 concludes the paper.

2 RELATED WORK

Visual air traffic analysis techniques and tools can be roughly divided into two classes, as follows.

Decision support systems, such as ATC systems, typically handle low-to-moderate size data sets, such as the region over an airport or city (Fig. 1 b), or thousands of trails over larger geographical areas. These tools provide sophisticated query mechanisms to support various ATC tasks. The Future ATM Concepts Evaluation Tool (FACET) is capable of quickly generating and analyzing thousands of aircraft trajectories (Bilimoria et al., 2001). It provides a simulation environment for the climb, cruise, and descent phases of an aircraft's flight. Traffic patterns are shown in 2D and 3D, under various current and projected conditions for specific airspace regions. Similar systems have been developed by Eurocontrol, the European Organization for the Safety of Air Navigation. For example, the Network Strategic Tool (NEST) (Eurocontrol, 2013) is a tool used by air traffic practitioners for airspace structure design and development, capacity planning and post-operations analysis, the organization of traffic flows, the preparation of scenarios for fast time simulations, and ad-hoc studies at local and network level. EPOQUES (Gaspard-Boulin et al., 2003) is a tool which gathers and analyzes radar recordings and audio communications. It proposes underlying techniques to treat Air Traffic Management (ATM) safety occurrences, such as helping operators to detect and analyze situations when two aircraft go

beyond safety distance. CoFlight (Thales, Inc., 2013) is a flight data processing (FDP) open-architecture framework for the storage, analysis, and visualization of 4D (spatio-temporal) flight data. A comprehensive list of over 50 ATC-related systems and tools is given in (GAIN Group, 2004). While such systems emphasize the importance of visualization for ATC systems, they all lack high visual scalability and/or the ability to show multiple data attributes at the same time. Specifically, there is no way to continuously navigate between the different levels of abstraction, which makes it harder to link global and local scale patterns.

Exploration systems, in contrast to decision support systems, aim at showing as much traffic data to the user as possible, without prior filtering, so the user can spot unexpected behavior. By next detecting outlier and/or mainstream patterns in such visualizations, users can focus on a subset of the data, and refine their understanding thereof. Many such systems employ a space-filling (also called dense-pixel, or image-based) metaphor (Mansmann et al., 2007): By trying to use each screen pixel to convey data, users can explore larger data sets on a wider range of levels of abstraction, from fine-grained and local patterns to coarse global patterns. Image-based techniques also naturally map to GPU implementations, which helps their computational scalability. For instance, (Willems et al., 2010) use density maps to show thousands of trajectories of nautical vessels on 2D maps and also to emphasize high-congestion areas. By next combining several density maps, a few attributes can be analyzed simultaneously (Scheepens et al., 2011). (Lambert et al., 2010b) use GPU techniques to quickly compute uncluttered layouts of large aircraft trajectories in both 2D and 3D (Lambert et al., 2010a). The FROMDADY system allows interactive linking and brushing of airplane trails to support complex queries in the entire attribute space recorded in the data set (Hurter et al., 2009). Density maps are effective to tackle the visual scalability problem, by aggregating spatially close information for trajectory analysis (Andrienko et al., 2011; Andrienko et al., 2012; Marzuoli et al., 2012). Multimodal interactions help users in posing complex queries with little effort (Letondal et al., 2013). Bundling techniques are effective in showing the coarse-scale connectivity structure of a set of trails that link a set of spatial locations in a clutter-free manner (Hurter et al., 2012; Holten and van Wijk, 2009; Ersoy et al., 2011; Cui et al., 2008). Bundling can also be used to show the dynamics of trails, *e.g.*, how flight patterns change over a geographical area over a week (Hurter et al., 2013). Focus+context interaction techniques help in further reducing clutter and posing complex spatial- and data- queries in trajectory visualizations (Hurter et al., 2011; Krüger et al., 2013).

3 VISUALIZATION TECHNIQUES

We now introduce our image-based visualization techniques for plane trails. Throughout the exposition, we use as running example the one-week French air traffic data set from (Hurter et al., 2013) (52K flights, about 900K recorded plane positions).

3.1 Data model

We model a flight path, or trail T , as a sequence of points

$$T = \{\mathbf{p}_i = ((x, y) \in \mathbb{R}^2, h \in \mathbb{R}^+, t \in \mathbb{R}^+)_i\} \quad (1)$$

which we order along increasing values of t_i . The points \mathbf{p}_i hold recorded samples of the plane’s position (x, y) , flying altitude h , and possibly additional quantities such as ground and air speed. Our data set is thus a collection $TS = \{T_i\}$. Attributes can be also defined at the trail level, e.g., the flight ID. At an even higher level, we can have attributes at the level of a group of spatially-and-temporally close trails, which we call a trail bundle (Hurter et al., 2013).

3.2 Multivariate animated visualization

Our main visualization techniques are *animation* and *density maps*, akin to (Scheepens et al., 2011; Willems et al., 2010). However, we take several different design decisions, leading to a different visualization, as follows.

First, we consider four instantaneous attributes (that is, sampled at all moments t_i , Eqn. 1):

- A1:** instantaneous positions of in-flight airplanes;
- A2:** height along flight trails;
- A3:** flight directions along trails;
- A4:** airplane flight speed along their flight trails.

Next, we construct a density map

$$\rho(\mathbf{x}) = \sum_{T \in TS} \int_{\mathbf{p} \in T} K\left(\frac{\mathbf{x} - \mathbf{p}}{h}\right) \quad (2)$$

by convolving the trail-set with a Gaussian or Epanechnikov (parabolic) kernel K of width h . ρ is subsequently interpreted as luminance to become the background of the visualization, similarly to (Scheepens et al., 2011). However, in contrast to (Scheepens et al., 2011), we use the density map only as a *context* visualization atop of which our actual fine-grained animation takes place, whereas (Scheepens et al., 2011) use the density map as their prime visualization vehicle. Figure 2 a shows the density map for the French airline data set. Bright white-gray areas show regions of intense traffic for the entire considered time range. Dark gray regions indicate areas where few or no flights were recorded in this period.

Next, we consider a so-called sliding time-window $w(t) = [t, t + \Delta]$, which moves with constant speed (given

by a user-controlled animation setting) over the considered time range. Given this time-window, we select all data points $\mathbf{p}_i \in TS$ for which $t_i \in w(t)$. Rather than drawing entire trails T atop of the background, such as e.g. (Scheepens et al., 2011) or (Hurter et al., 2013), we now consider *trail segments* $T_\Delta(t)$ which contain all trail sample points falling in w . We draw these trail segments, textured with a transparency (alpha) texture. This texture is built by placing at the sample point positions \mathbf{p}_i a train of 1D Gaussian half-pulses ϕ_i tangent to the trail segments $(\mathbf{p}_i, \mathbf{p}_{i+1})$. The pulses ϕ_i are scaled so that they are 1 at the location of \mathbf{p}_i and near zero at a distance $\delta \mathbf{v}_i$ downstream the flight path, where \mathbf{v}_i is the instantaneous plane speed at \mathbf{p}_i and δ is a user-set parameter. The final texture is built by modulating the pulses ϕ_i with a large 1D Gaussian envelope Φ_Δ placed over w and summing up the modulated values (see Fig. 3).

Texturing serves two purposes, as follows. First, setting both Δ and δ to very low values creates images where the arrow-like (high to low alpha) shapes created by ϕ_i , and their motion due to the sliding window, shows the *instantaneous* plane positions at a given time moment (**A1**) as well as their motion along trails (Fig. 2 a). In contrast, setting δ to low values but Δ to larger values creates ‘trains’ of arrow-like shapes that slide along trails. Figure 2 b shows a snapshot from such an animation. Here, short pulses indicate slow-motion planes – indeed, slower planes mean closer-spaced sample points, thus shorter pulses. Analogously, longer pulses show fast planes. Finally, we can add a third attribute to the visualization by using color mapping. For instance, in Fig. 2 b (inset), we use a blue-to-red (rainbow) color map to map altitude. We see here a fine-grained blue trail segment indicating a slow, low-altitude, outlier flight in an area with fast (long pulses) and higher (green) flights (**A4**).

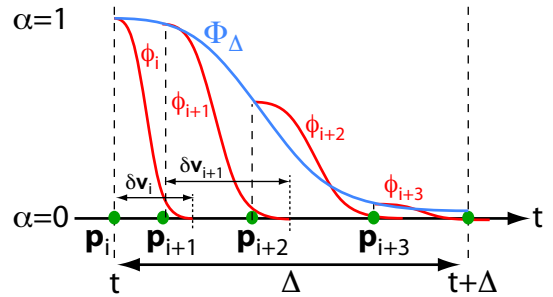


Figure 3: Construction of directional pulses for animation.

Increasing both δ and Δ also allows us to smoothly navigate from instantaneous views on the data to more global views. Figure 2 c shows this for Δ set to roughly 8 hours and δ to 4 hours respectively for our one-week flight data set. Colors map flight altitude (**A2**). Blue spots indicate regions densely populated by landing zones (airports). Warm lines show in-flight routes. By looking at the latter, we can see that most studied flights have the same altitude. This observation correlates with flight

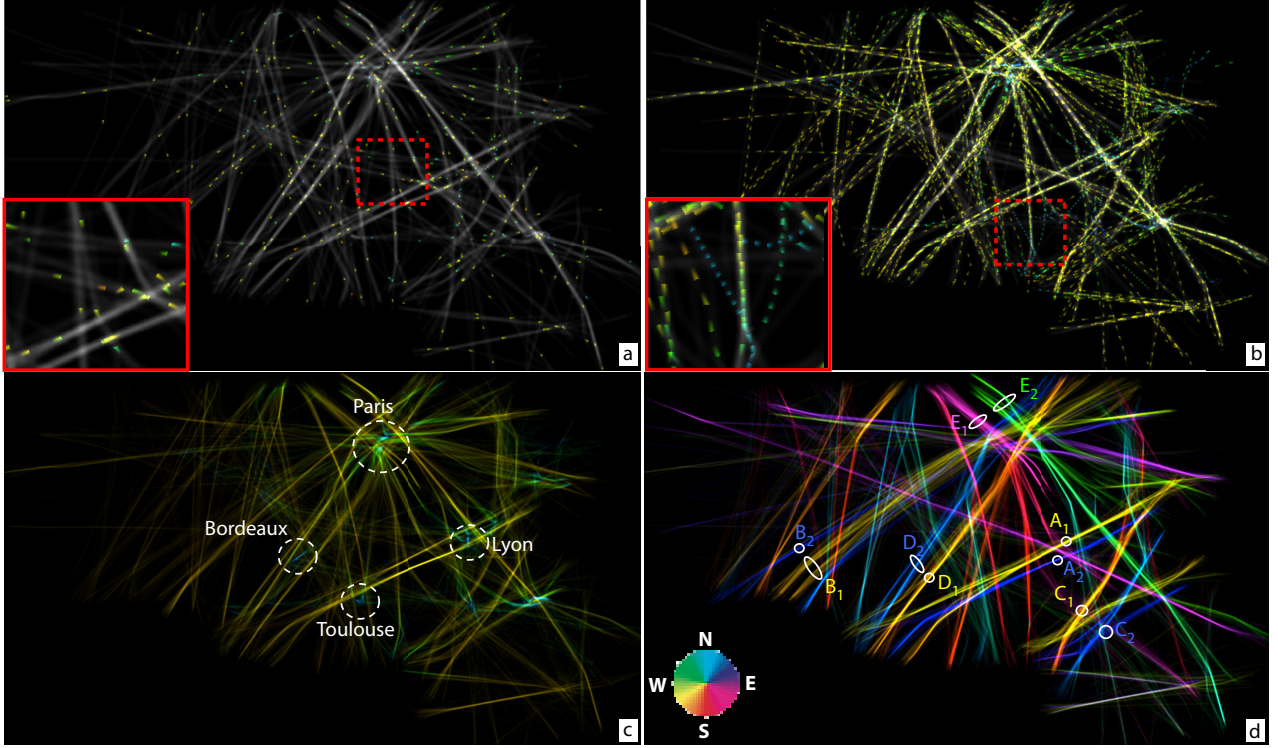


Figure 2: Animated multivariate visualization, French airline data set. (a) Instantaneous plane positions, with color-coded height. (b) Trail segments over short time periods, with color-coded height. Trails over entire studied one-week period with color coding height (c) and direction (d).

rules for civil aircraft for the studied territory (France). Figure 2 d shows a similar map, with trails colored now using a directional hue color map (see color wheel in the image), thus addressing **A3** over the entire studied time period. Directional color coding lets us discover several close-and-parallel, opposite-direction, flight paths, e.g. A_1, A_2 ; B_1, B_2 , C_1, C_2 and D_1, D_2 (going southwest-northeast and conversely); and E_1, E_2 (going roughly northwest to southeast and conversely). Similar patterns (not shown here for conciseness) exist for almost all the other similar-size time intervals in the studied 7-day period. From such images, we can conclude that flights linking pairs of airports follow parallel paths but are structurally not overlapping in space.

However useful in showing the flight directions, flight speed, and overall flight locations, the above visualizations suffer from a certain amount of clutter, especially for large values of Δ . Indeed, in such cases, our trail-segment set contains many crossing flights, especially in high-density areas such as close to airports. Understanding flight patterns in such areas is important for many ATC planning tasks (Letondal et al., 2013; Hurter et al., 2009). We further help users in getting clearer, less cluttered, insight in such areas by using several transfer functions, as follows:

Alpha transfer function: Consider, for instance, that we are interested in low-altitude flight segments (close to airports). To focus on these regions, we modulate the pulse textures ϕ_i with a transfer function $f(h) = (\frac{h_{max}-h}{h_{max}})^{k_\alpha}$, where h and h_{max} are the altitude and its maximum value respectively. Values of $k_\alpha < 1$ render low-altitude trail segments gradually transparent, allowing to focus on the high-altitude ranges. Values of $k_\alpha > 1$ render high-altitude trail segments more transparent, allowing to focus on low-altitude ranges.

Color transfer function: Consider, for instance, that we color map the altitude attribute. If we are interested in focusing on altitude variations for the low-altitude (close to airport) range, we need to dedicate more dynamic range to this signal range. To do this, we apply a transfer function $f(x) = x^{k_{color}}$ to the normalized altitude attribute prior to color mapping. Values of $k_{color} < 1$ emphasize high altitude ranges. Values $k_{color} > 1$, in contrast, emphasize low altitude ranges.

Figure 4 shows the effects for our French airline data set. Image (a) shows the effect of $k_{color} = 1$ and $k_\alpha = 2$. As the high-altitude trail segments become more transparent, we can now better focus on the airport zones and thus the landing and take-off trail segments. These are apparent on the image as colder colors (blue). Image (b),

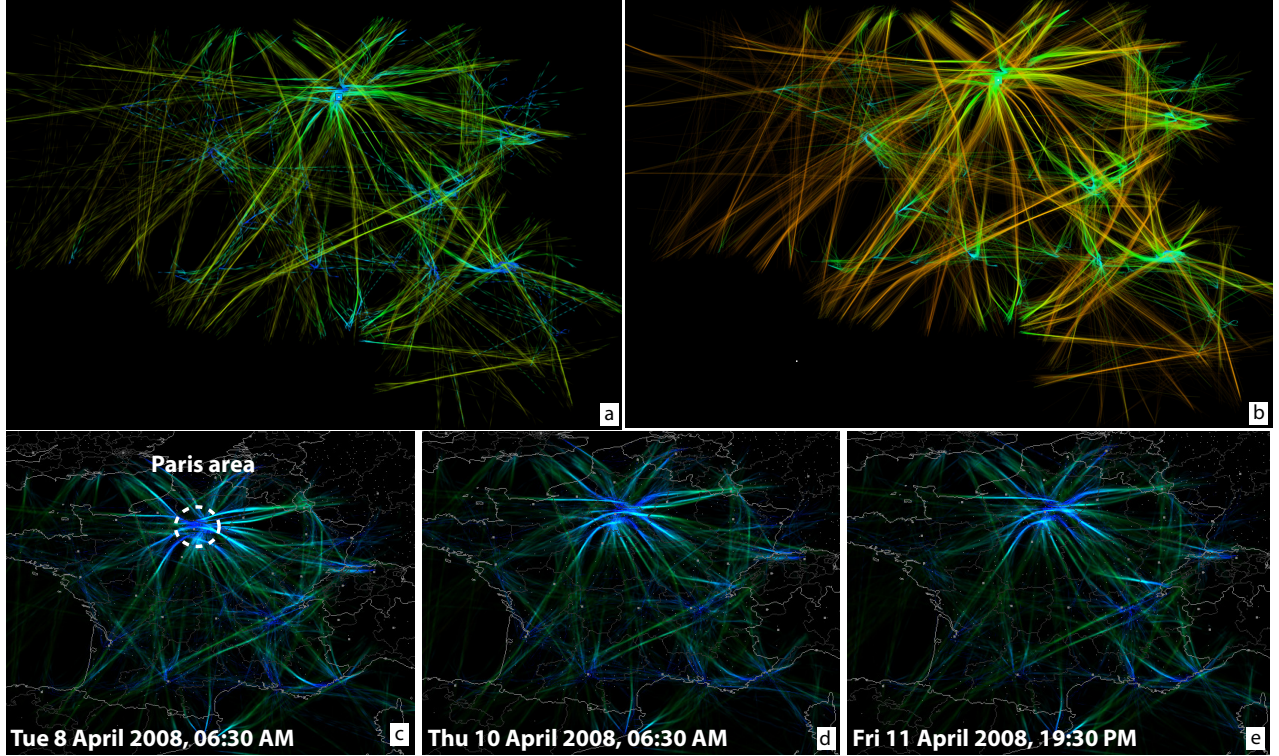


Figure 4: Emphasizing specific flight ranges and decreasing occlusion by color and alpha transfer functions.

taken for a longer time-window Δ value, shows the effect of $k_{color} = 0.5$ and $k_{\alpha} = 1.5$. We see now more and longer trails, since Δ is longer. However, the clutter due to over-draw stays limited, due to the fading out of high-altitude trail segments caused by k_{α} . The low k_{color} value allows us to visually separate the warm-colored cruise trail segments (which have higher altitude) from the cold-colored landing and takeoff segments (which have lower altitude). Images (c-e) show three snapshots from our one-week period taken at different moments of the morning and evening, for $\Delta = 30$ minutes. Here, by using $k_{\alpha} = 3$, we are able to de-clutter even more of the crowded airport regions, and see the so-called ‘approach lanes’ of the planes, *i.e.* the general paths that planes take when taking off or landing at an airport. Although images (c-e) are for three different days and two different times of day, we notice that the approach lanes above the Paris area are quite similar. This is not a trivial finding since, if we look at other times of day, such patterns are quite different. The found explanation (in discussions with ATC controllers) is that planes that land and/or take off early in the morning or late in the evening are typically long-distance hauls, which have more stable approach lanes than shorter-range flights common during the day.

3.3 Animation and bundling

As shown so far, our flight visualization offers several scales, or levels of detail, at which the data can be examined – ranging from instantaneous plane positions to trail fragments and ending with large trail sets over several days. However, apart from this *temporal* multiscale, we can also exploit the *spatial* multiscale of our trail data. Looking at *e.g.* Fig. 2 d, we see that trails come naturally grouped in sets of closely spaced, relatively parallel, trails. This observation has been exploited by many bundling algorithms that simplify the visualization by bringing together all trails in such sets, *e.g.* (Hurter et al., 2012; Holten and van Wijk, 2009; Ersoy et al., 2011; Cui et al., 2008). The resulting images, although they distort the spatial information, are much more effective than trails in showing the connectivity patterns between airports, and how these change in time.

Recently, (Hurter et al., 2013) have shown how trail bundling can be applied to airline trails, by applying the efficient and robust KDEEB bundling algorithm (Hurter et al., 2012) to a so-called streaming graph containing only trails whose start time moment falls within a sliding time-window. However, their solution does not show any additional attributes atop of the emerging bundles, such as flight directions, height, or speed. We extend here this approach, by combining bundling with our multivariate

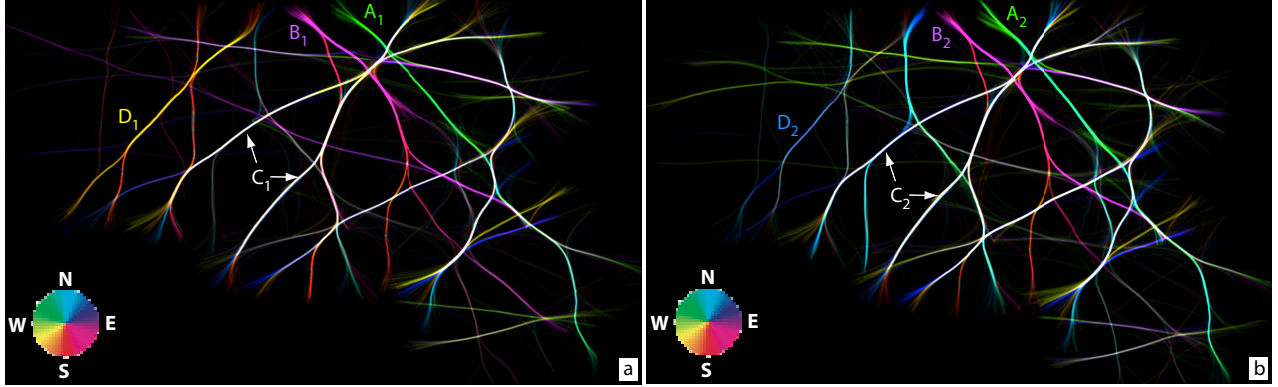


Figure 5: Emphasizing airport connection patterns by trail bundling.

attribute-based animations. In detail, we apply (Hurter et al., 2013) to trails selected by our time-window $w(t)$. This delivers a set of bundled trails. Next, we project on these trails the attribute values of the corresponding sampling points (for identical time moments) from the original, unbundled, trails. Finally, we use the visualizations described in Sec. 3.2 to create the final images.

Figure 5 illustrates this. Images (a,b) use the same color coding as in Fig. 2 d. However, the trails are now given by two frames of the *bundled* flight graph, which correspond to two moments in two different days in our one-week data set. Since trails are bundled, geographical (spatial) information is lost: Bundles indicate now just *connections* between airports, rather than actual flight paths. Still, directional color-coding is useful to show temporal insights. First, we see that the connection pattern is roughly identical for the two studied moments. Flights in bundles *A* and *B* keep their directions over time, respectively northwest (green) and southeast (pink). Flights in the big central white bundle structure *C* go equally in both directions at both studied moments, since white is the result of additively blending opposite colors in our color map. In contrast, flights in bundle *D* go southwest (yellow D_1 in Fig. 2 e) and then return northeast at moment 2 (blue D_2 in Fig. 2 f). All the other visualizations described in Sec. 3.2, such as animating pulses along bundles to show flight directions, or using transfer functions to focus on specific data ranges, are further available.

3.4 Congestion detection

An important and frequently occurring task in movement data analysis is detecting and examining so-called *congestion areas*, i.e. spatial zones where many vehicles are present at a given time moment (Scheepens et al., 2011; Hurter et al., 2009). In ATC, such areas are particularly important to prevent air traffic congestion and, thus, delays or an increase in fuel consumption. On smaller spatial scales, congestion areas become collision areas, i.e. zones where a high risk of vehicle collision exists. Corre-

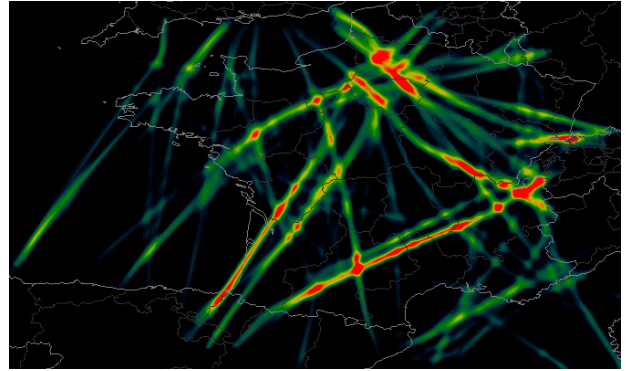


Figure 6: Congestion detection. The kernel size corresponds to a time-interval of 30 minutes. Alpha blending is used to focus on higher flights.

lating the appearance of such zones with other parameters can give important insights in the reasons why such problems occurred and ways to solve them (Eurocontrol, 2013; Gaspard-Boulinc et al., 2003; Bilimoria et al., 2001).

An early, and relatively simple, approach to congestion area detection was given by (Scheepens et al., 2011): By visualizing the density map ρ (Eqn. 2), we can detect zones of high vehicle densities. However, this solution was proposed in a static setting: There is a single density map computed for the entire studied time period. As such, dynamic congestion patterns that occur and disappear on smaller time-scales are not visible. Secondly, this basic solution does not assume there is a higher probability of collision in the direction of vehicle motion and for rapid vehicles than for other situations.

We extend this idea by using anisotropic kernels K in Eqn. 2. In contrast to the isotropic radial kernel, such kernels are larger in the direction of instantaneous motion of a vehicle than in other directions. A simple way to implement this is to use *e.g.* elliptic kernels whose large axis is tangent to the trail and scaled to be equal to the instantaneous velocity. A further refinement involves using asymmetric kernels, which are longer in the motion

direction than in the opposite direction, thereby modeling the fact that congestion or collision is more probable in *front* of a moving vehicle than behind it. Other kernels can be immediately used to model other types of congestion probabilities, as and when desired.

Figure 6 shows the result of visualizing this congestion density map for the French airline data set. Here, we color mapped the quantity $\max(\rho - 1, 0)$ to a rainbow color map. Indeed, ρ is by construction equal or larger than 1 at every plane location, and only values larger than 1 indicate a congestion probability, *i.e.*, the overlap of two kernels corresponding to two different planes. We also used $k_\alpha = 0.2$ to focus on higher-altitude trail segments, as we are more interested to detect and assess in-flight congestion rather than congestion close to or on the airstrips. The kernel size was set to be equivalent to a duration of 30 minutes, thereby modeling a use-case where if several planes at high altitude get closer to each other than a flight time of 30 minutes, we consider the area as being congested. The red patterns visible in the image delineate quite clearly the emerging congestion patterns. These patterns are not (easily) visible using any of the earlier-used visualizations. We notice that the congestion areas are, in most cases, well aligned with the the main flight routes, which is expected. However, we also see a few red blobs which do not follow the elongated structure parallel to these routes. These indicate congestion areas that occur at the intersection of several routes rather than on a single route.

4 RESULTS

We used our visualization to analyze several data sets over different space and time periods. Statistics for the data sets shown in this paper are given in Tab. 1. Besides the French data set, we show also a data set with three days of flights over Europe and one with one-month flights over the entire world. Our goal was the *explorative* scenario outlined in Sec. 2: Given a large and unknown data set, can we (as users) quickly form a general impression on the distribution of flights in terms of spatial location, direction, speed, and height? Secondly, can we discover outlier flight patterns, which diverge, in some significant way, from the overall flight patterns in the same data set? Below we present several of our findings.

Outlier landing/takeoff patterns: In Fig. 4 (d-e), we found that landing/takeoff patterns over the Paris area, for three moments, are quite similar. However, we cannot generalize to infer that such patterns are constant for *all* moments. Also, the zoom level in Fig. 4 is too low, so potential small-scale pattern changes would not be visible.

We repeated the experiment shown in Fig. 4 (d-e) at

Statistics	French air-traffic	Europe air-traffic	World air-traffic
start date	06/04/2008	01/06/2013	01/06/2013
end date	12/04/2008	03/06/2013	30/06/2013
# flights	52547	50984	748057
# sample points	870880	873240	14711646

Table 1: Data set statistics for examples in this paper.

a finer zoom level. Also, we set Δ to 24 hours, to show more data in one animation frame, thereby allowing us to move the animation faster to cover a longer time period quicker. Next, we watched the animation for our one-week data set. Pattern changes are easily spotted as changes in the animation. We thus discovered that pattern changes indeed exist. Figure 7 shows three frames from this animation, for three different days. We quickly see that the Saturday traffic is much more intense than on Sunday and Tuesday. This confirms the expected week variation of flight patterns. More interestingly, the Tuesday landing/takeoff routes are quite different than the ones for the other two days. To explain this further, we looked up data for wind direction around the Paris area for these three days, and found out that the wind patterns on Tuesday were quite different than for the other two days. This explains our finding, as ATC rules indicate that landing/takeoff flight segments are indeed computed based on wind directions.

Global flight patterns: We now consider a larger data set, covering the entire world. The data, available online (PlaneFinder, 2013), is gathered continuously by hobbyists that record ADS-B plane feeds (ADS-B, 2013) used by commercial and private planes to transmit their name, position, altitude, call sign, status, and other information, and consolidated into a global server. ADS-B is gradually replacing radar as the most efficient method for ATC, so our visualizations will potentially become directly relevant for ATC-related tasks in the near future. In contrast to the French airline data set, obtained directly from the French ATC authorities, the world data set is far less uniformly sampled, depending on the position of hobbyist receivers throughout the world. However, this data set is orders of magnitudes larger (see Tab. 1). We processed this data to create the trails data set necessary for our visualization, by matching IDs of the same flight, removing duplicate sample points (coming from different beacons), and separating flights having the same ID that occur during different days.

Figure 8 shows an overview of the world traffic on June 1, 2013. Image (a) is a snapshot from (PlaneFinder, 2013), showing plane *positions* at one moment during the day with icons. Besides flight densities, little is visible on this image. Image (b) shows our visualization of flight *routes* for that day, color-coded by flight direction. As for



Figure 7: Height-colored trails over a duration of 24 hours with an alpha-based emphasis on low flights (and airports). We see a clear difference in landing directions Sunday vs Tuesday. Saturday shows a significant increase in traffic around Paris.

the smaller French data set (Fig. 2 d), we see here too that flights linking the same (close) airports but having different directions follow parallel, but separated, lanes – such as the broad one between Europe and the US. However, the densely flown regions, such as Europe, are too cluttered at this scale. One solution to de-clutter is to reduce the parameters δ and Δ , to focus on shorter time-ranges. Image (c) shows this result. Here, the arrow-like glyphs become visible and as such indicate the flight directions more clearly (see insets). As such, the European region also becomes more de-cluttered. To further de-clutter and obtain local detail, we zoom in over Europe (image (d)), and increase back δ and Δ to see full one-day trails, like in image (b). We can again see here the lane separation patterns, such as the one linking the Canary islands with the mainland and connecting the main hubs, *e.g.* London, Paris, and Amsterdam with the rest of the map. Image (e) shows the same region, this time color-coded by altitude. Low-flight zones such as airport areas are blue, and cruise segments are green. We see that the average cruise heights over Europe are quite similar. The sizes of the blue spots indicate the extent of low-flight zones close to airports. Interestingly, the entire of south-east Britain is such a zone, which is not crossed by any high-altitude flight (yellow trails). In contrast, the Paris area shows a similarly-sized blue zone, but which gets crossed by quite many high-altitude flights. Image (f) shows the Europe traffic with trail bundling, colored by flight directions. We notice here many white bundles: These are parallel *and* close trails which have nearly equal counts of flights in opposite directions. Indeed, since the KDEEB algorithm works by grouping trails in distance order, trails that end up in the same bundle are by construction the closest ones to that bundle’s location. And, secondly, since trail colors are additively blended *and* we use directional hue-coding, we achieve gray (or white) when a bundle contains (nearly) equal trail amounts running in opposite directions. We can thus infer that most trail groups over Europe over the

considered day contain roughly equal numbers of flights in opposite directions. This situation was different for the two considered day *moments* for the *French* airspace shown in Fig. 5. Thus, we infer that, at a coarser day-over-Europe scale, air traffic is more balanced. Finally, we see in Fig. 8 f also a few outlier colored trails (see markers in image). These are groups of flights that go in a *single* direction, *i.e.*, there are no opposite-direction flights in the same spatial region for the entire considered day.

5 DISCUSSION

Several aspects are relevant to our presented technique, as follows.

Scalability: We implemented our visualization in Python and C++, using OpenGL pixel shaders for the rendering part (texture computation, blending, transfer functions, and congestion map, see Sec. 3). For bundling (Sec. 3.3), we use a novel CUDA-based implementation of the KDEEB principle (Hurter et al., 2012), as follows. First, we compute the density map using separable 1D convolution kernels, and a gathering design, rather than the scattering design using 2D OpenGL texture sprites in KDEEB. Secondly, we parallelize all operations (density map computation, trail advection, and trail re-sampling), as compared to only density computation in KDEEB. Table 2 shows our timings on a 2.6 GHz Windows PC with a NVidia 690 GTX card, for various trail selections. The bundling cost is roughly linear with the number of sample points. Compared to the results in (Hurter et al., 2012), our bundling is about *30 times* faster, on identical hardware. The computational complexity of our technique is linear in the number of trail sample points falling in the considered time-window of length Δ . Given the above-mentioned design decisions, we can all in all create real-time animations of flight data for a few million

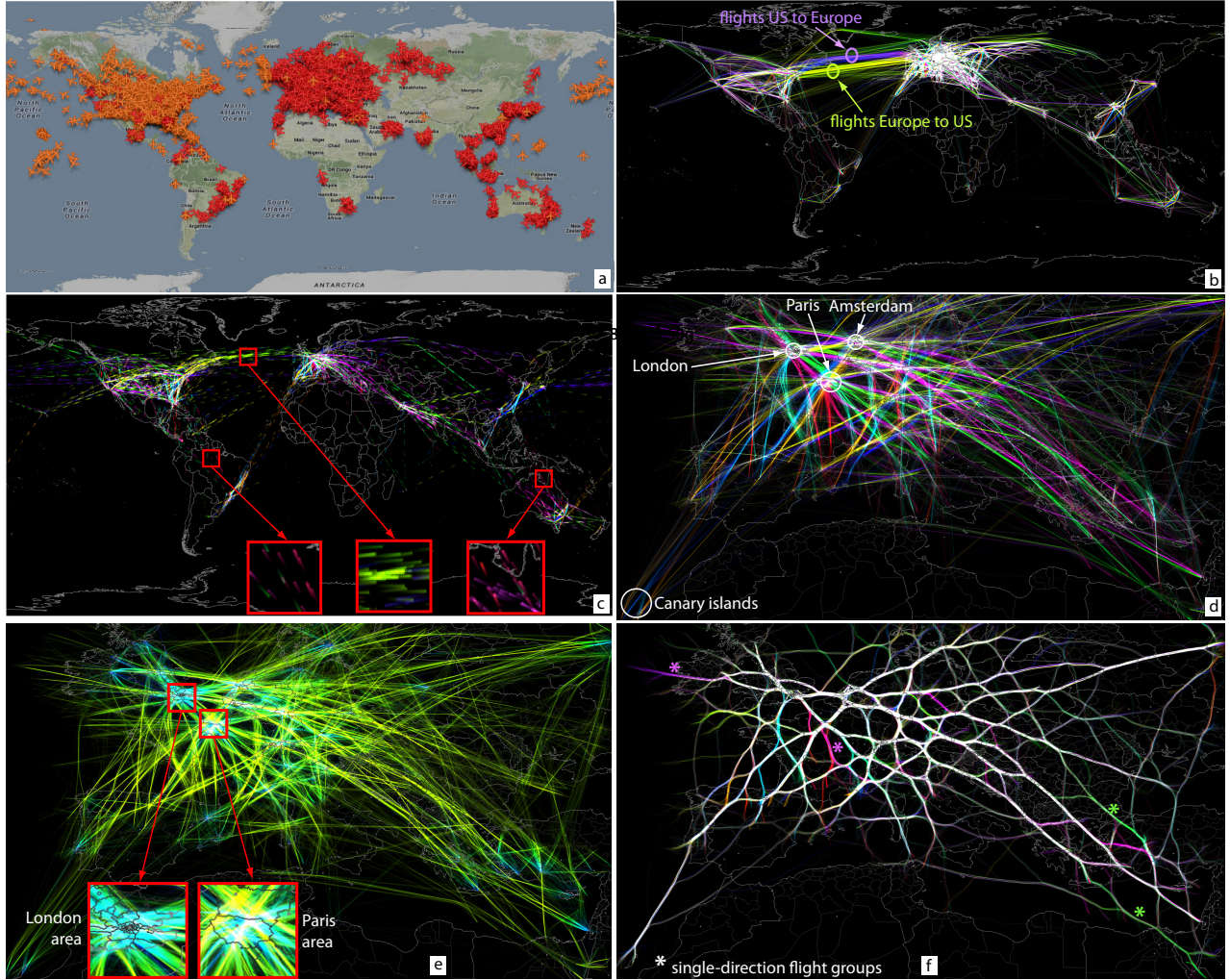


Figure 8: (a,c) Overview of world traffic, June 1, 2013. (d-f) Details over Europe (see Sec. 4).

sample points. This performance was not achievable with earlier techniques (Hurter et al., 2013; Hurter et al., 2009; Eurocontrol, 2013; Krüger et al., 2013).

Statistics	# flights	# sample points	bundling time (msecs)
Data set 1	50984	683216	74
Data set 2	23433	886323	89
Data set 3	50984	1280680	124

Table 2: CUDA bundling statistics.

Limitations: While our technique has significantly less visual clutter than *e.g.* (Hurter et al., 2009; Hurter et al., 2013; Krüger et al., 2013) by means of transfer functions and bundling, highly dense flight areas viewed at a coarse scale will still have a high amount of overlapping flights. This problem is solved in (Scheepens et al., 2011) by showing only aggregated information. In contrast, we

choose to tolerate the clutter to be able to show individual outliers in such areas. To increase resolution, we use a large 60-inch touchscreen, which makes finer-grained patterns easier visible. A second limitation concerns the number of attributes that we can show simultaneously on a trail – currently, this is limited to three (speed, direction, and altitude). Showing more attributes is an open challenge to all similar research.

6 CONCLUSIONS

We have presented a set of visualization techniques for the interactive exploration of very large movement data sets emerging from Air Traffic Control. Our main goals were to achieve high information density with limited clutter, present several movement attributes such as altitude, position, and speed at the same time. We achieve these goals by following an image-based visualization de-

sign based on density maps (to show amount of flights), animation (to show direction and change in flight patterns over time), and graph bundling (to show coarse-scale similar patterns and their change over time). We achieve computational scalability by using a fully GPU-based implementation using pixel shaders and CUDA. The visualization design and implementation also allows users to smoothly navigate, in both space and time, between local detail and global patterns. We demonstrated our techniques on several data sets ranging from hours over a single country to one month over the entire world. Further information and material is available online at <http://www.cs.rug.nl/svcg/SoftVis/FlightVis>.

Although visual scalability is still challenged by the sheer amount of information to be shown, our method is considerably more scalable both in visual space and computational complexity than current methods used for the same types of data sets and analysis. In the future, we plan to augment our visualization by adding interactive queries in order to enable users to compare and search spatio-temporal patterns of interest, and also enhance the image-based design to allow for the display of more data attributes at the same time.

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